Amendments to the Claims:

1. **(Original)** A manipulator-type robot, which has an internal cable routed through an inside of a manipulator so as to establish a connection to an external device, the robot comprising:

inside connectors each of which is directly or indirectly connected to a predetermined signal line out of a plurality of signal lines constituting the internal cable; and

outside connectors each of which is directly or indirectly connected to a predetermined signal line out of a plurality of signal lines from an external device,

wherein, a different connection route is obtained by a selective connection between the inside connectors and the outside connectors.

2. **(Original)** The manipulator-type robot of claim 1, wherein the signal lines from the external device are signal lines from a plurality of external devices.

3. **(Original)** The manipulator-type robot of claim 1, wherein the signal lines fed from the external device are bundled together as an external cable connected to an integrated external device that contains a plurality of external devices.

4. **(Currently amended)** The manipulator-type robot according to ~~any one of~~ claim 1 ~~through claim 3~~, wherein a connection case for making a cable connection to the external devices is disposed so that the inside connectors establish a connection to the outside connectors in the connection case.

5. **(Currently amended)** The manipulator-type robot according to ~~any one of~~ claim 1 ~~through claim 3~~, wherein the selective connection between the inside connectors and the outside connectors offers a wide range of uses.

6. **(Currently amended)** The manipulator-type robot according to ~~any one of~~ claim 1 ~~through claim 3~~, wherein the internal cable routed through the inside of the manipulator contains various kinds of signal lines.

7. **(Original)** A manipulator-type robot, which has an internal cable routed through an inside of a manipulator so as to establish a connection to an external device, the robot comprising:

first inside connectors each of which is directly or indirectly connected to an end of a predetermined signal line out of a plurality of signal lines constituting the internal cable;

second inside connectors each of which is directly or indirectly connected to an other end of a predetermined signal line out of a plurality of signal lines constituting the internal cable,

first outside connectors each of which is directly or indirectly connected to a predetermined signal line out of a plurality of signal lines fed from first external device; and

second outside connectors each of which is directly or indirectly connected to a predetermined signal line out of a plurality of signal lines fed from second external device,

wherein, a different connection route is obtained by at least any one of a selective connection between the first inside connectors and the first outside connectors and a selective connection between the second inside connectors and the second outside connectors.

8. **(Original)** A manipulator-type robot with a manipulator, the robot comprising:

first outside connectors each of which is directly or indirectly connected to a predetermined signal line out of a plurality of signal lines fed from a first external device; and

second outside connectors each of which is directly or indirectly connected to a predetermined signal line out of a plurality of signal lines fed from a second external device,

wherein, the first outside connectors and the second outside connectors are disposed in the manipulator, and a different connection route is obtained by a selective connection between the first outside connectors and the second outside connectors.

9. **(Original)** The manipulator-type robot of claim 8, wherein a connection case for making cable connection to the external devices is disposed so that the first outside connectors are connected to the second outside connectors in the connection case.

10. **(Currently amended)** The manipulator-type robot of claim 8 ~~or claim 9~~, wherein the second external device is connected to the first external device via the second external connector and the first external connector when the first external device is located away from the robot, and the second external device is located adjacent to the robot.

11. **(Original)** The manipulator-type robot of claim 10, wherein the first external device is a controller for controlling the manipulator-type robot, the second external device is a peripheral device including a positioner and a sensor.

12. **(New)** The manipulator-type robot according to claim 2, wherein a connection case for making a cable connection to the external devices is disposed so that the inside connectors establish a connection to the outside connectors in the connection case.

13. **(New)** The manipulator-type robot according to claim 3, wherein a connection case for making a cable connection to the external devices is disposed so that the inside connectors establish a connection to the outside connectors in the connection case.

14. **(New)** The manipulator-type robot according to claim 2, wherein the selective connection between the inside connectors and the outside connectors offers a wide range of uses.

15. **(New)** The manipulator-type robot according to claim 3, wherein the selective connection between the inside connectors and the outside connectors offers a wide range of uses.

16. **(New)** The manipulator-type robot according to claim 2, wherein the internal cable routed through the inside of the manipulator contains various kinds of signal lines.

17. **(New)** The manipulator-type robot according to claim 3, wherein the internal cable routed through the inside of the manipulator contains various kinds of signal lines.

18. **(New)** The manipulator-type robot of claim 9, wherein the second external device is connected to the first external device via the second external connector and the first external connector when the first external device is located away from the robot, and the second external device is located adjacent to the robot.